Maximizing Maximum Time of a Dynamical System Through Optimal Radius of Acceleration Calculation

Parker Emmerson

October 2023

1 Introduction

In this paper, we will examine the relationship between the maximum time T_{max} and the radius of acceleration r in a dynamical system. We will begin by deriving an upper bound for T_{max} in terms of r and the product of the driving force with the associated time constant τ. We will then examine two conditions determining how the radius of acceleration should be calculated in order for this inequality to be satisfied. Finally, we will use these conditions to derive a lower bound for r and calculate its values for different values of θ and w. Through this analysis, we hope to shed light on the optimal way to calculate the radius of acceleration in a dynamical system in order to maximize T_{max}.

$$T_{max} \leq \frac{\tau}{r(\tau)}, for \tau \leq \frac{r(\tau)^2}{2c}. \tag{1}$$

$$2 \limsup_{\tau_{max} \to \infty} 2rq(1-w)^q \leq \tau_{max} \leq c[r(\tau)-w^q]r' - q\tau(r(1-w)^q)' \leq r(\tau) - w^q \leq r' + q\tau(r(1-w)^q)', \tag{2}$$

$$r = r(\tau) \to \sqrt{\tfrac{2r(r^2-2c^2q\tau)}{c^2}}$$

$$\mathrm{r}(\tau) \leq r_{max} \tfrac{c^2}{c^2 q e^{c(r^2-2c^2q\tau^2)}}, for \tau \leq \tfrac{r^2}{2c}.$$

$$r' \leq \tfrac{c^2 r_{max}}{1-e}$$

$$\mathrm{r}_w \leq \left(r_{max} + \tfrac{c^2}{1-e}\right) c \cos(2\theta_w)$$

$$= r_{max} \left((c^2+c)\cos(2\theta_w) - \tfrac{c^2}{1-e}\right).$$

$$P_{1-D}(r) = (r^2 - a_1)(r^2 - a_2) \tag{3}$$

$z(\theta, r) \geq 0 > c$ and $a \leq m < a_m$. The lower bound for m is given by $|\theta_+ - \theta_-| = m$, at which the values r_c and $r_{p(+)}$ satisfy $m = |\theta_r| = \tan(\theta_r)$ and $m = r_c - \max((0, \frac{|r_{p(+)}|}{\sin^2(\theta_- - \tan^{-1}(\theta_r^{-1})))^2, 0)}$ respectively.

$z(\theta_r,\pi) = r^2(\pi,\theta_r) - \pi c(\pi,\theta_r)^2$
$(a(n), f(n), b(n), c(n), z(n), m(n), Z(n)) = \{(0, \frac{8(f(a_p)-\frac{1}{4})^2}{(a_p)^2}, 0),$
$(\tan^{-1}(\tan(\theta_r))), (f(n)), (0,$
$-|\theta + (a_m - N(n))|, 0),$
$(|\angle_c(\pi,\theta_p)| + |\angle_c - 1(\pi,\theta_c) + \frac{4\pi}{3}), (z(n)), f(n), Z(n)\}$
$Z(n) = 0, n \in \{0, ...nP-1\}$
$A(n) = 1$

$$\begin{aligned} \langle \partial\theta \times \vec{r}_\infty \rangle \cap \langle \partial\vec{x} \times \theta_\infty \rangle &\rightarrow \{\langle \partial\theta \times \vec{r}_\infty \rangle \cap \langle \partial\vec{x} \times \theta_\infty \rangle\} = \{\langle \partial\theta \times \vec{r}^* \rangle \cap \langle \partial\vec{x} \times \theta_\infty \rangle\} \\ &= \{\langle \partial\theta \times \vec{r} \rangle \cap \langle \partial\vec{x} \times \theta_\infty \rangle\} = \frac{\mathbf{u}}{c} \langle r,\tau\rangle \cap \left\{ \left\langle \phi\tau - \pi + \frac{\pi}{\phi}, \phi(\phi-1)\frac{\tau}{c} \right\rangle \right\} \\ &= \frac{\mathbf{u}}{c} \langle r,\tau\rangle \cap \{r,\tau\}, \qquad (4) \end{aligned}$$

(4)

1. Consider the ray $\xi\vec{r}_s = \vec{x}$, then eq:RayDefinition is a discrete set and eq:DensifiedSweepingSubnetToER is not applicable.
2. If $\xi - \mathtt{r}\vec{r}_s \neq \vec{x}$ so that $\xi - \mathtt{r}\exists\vec{r}_s$, then $\xi - \mathtt{r}\mathcal{P}$ considered the condition $\xi - \mathtt{r}F_e(\phi(\vec{r}_s)) \equiv \vec{r}_s = \vec{r}'_s$ for $\xi - \mathtt{r}\vec{r}'_s = \mathcal{P}^{-1}(\vec{r}_s)$. Lemma **??** implies that $\xi - \mathtt{r}\vec{r}_s$ starts at $\xi - \mathtt{r}\vec{x}$ and terminates at $\xi - \mathtt{r}\vec{r}$.
3. Let $\mathtt{r} = \xi E_\xi := \{r,\tau\} \cap \langle \mu = \Phi(\infty)\rangle$. Since $\mathtt{r} = \xi\Phi(\infty)$ is a component of $\mathtt{r} = \xi\vec{r}_{max} = \infty$, the tangent $\mathtt{r} = \xi\mu = \Phi(\infty)$ is orthogonal to $\mathtt{r} = \xi E_\xi$. The condition $\mathtt{r} = \xi\phi(\mu)\ \mathtt{r} = \xi \notin \langle\infty\rangle$ is not valid for $\mathtt{r} = \xi\Phi(\infty)$ by Equations (**??**, **??**).

eq:SaturationProof,

$$\begin{aligned} 0 &= \log_\phi \chi_{\{r=\phi(\xi)\}} = \mathcal{E}(\mu) \\ &= \psi^*(\mu, \Psi(\mu), f) - \lambda + \psi(f(\mu)) \\ &= -\log_\phi \mu - \lambda + \psi(\infty) \\ &= -\log_\phi \mu - \log_\pi r + \psi(\infty) \\ &= -\log_{\log_\pi \mu + \frac{1}{\phi(\mu)}} r + \psi(\infty) \\ &= -\log_{\log_\pi \mu} \left(r - c^{-1}\psi^*(\log_\pi \mu, c) + \psi(\infty) + c\log(-\log_\pi \mu)\right) + \psi(\infty). \end{aligned}$$

$\phi(\cdot) = r - c^{-\psi^*(\cdot,c)},$
$\phi(f_{min}) = f_\xi = 1,$
$\Phi \circ \partial\theta \times f\left(cf_{min}^{-\tau}\right) = \partial\theta \times \vec{r} + \vec{g}_e$
$\vec{g}_u.$

$$\|p_\perp(\tau,p)\| = \frac{\sqrt{(c/2 - f_d)\left(\frac{p_\tau}{m}\right)^2}}{1 + (c/2 - f_d)^{-1}},$$

$$\|c/2 - f_d(deg)^{-1} 1 \frac{1}{\cos\theta = p \cdot p'} \| = \ell(\theta, \mu),$$

$$f(\tau) := \alpha, \alpha \in \left\langle \left\langle \tau_{min} + \frac{\tau}{\alpha}, \tau \pm \frac{\tau}{\alpha} \right\rangle (\tau_{max}) \right\rangle,$$

$$r := \left(\alpha * \cos\left(-\pi \cdot \frac{\tau}{c \cdot \alpha}\right), 2\alpha^{-1} + 1 \right) \in \left\langle \left\langle \tau_{min} + \frac{g(\tau)}{\alpha}, \tau \pm \frac{1}{\alpha} \right\rangle (\tau_{max}) \right\rangle,$$

or

$$r := \left(f(\tau)^{\circ} * \cos\left(-\pi * \frac{g(\tau)}{f(\tau)} \pi\right), 2f(\tau)^{\circ -1} + 1 \right)$$

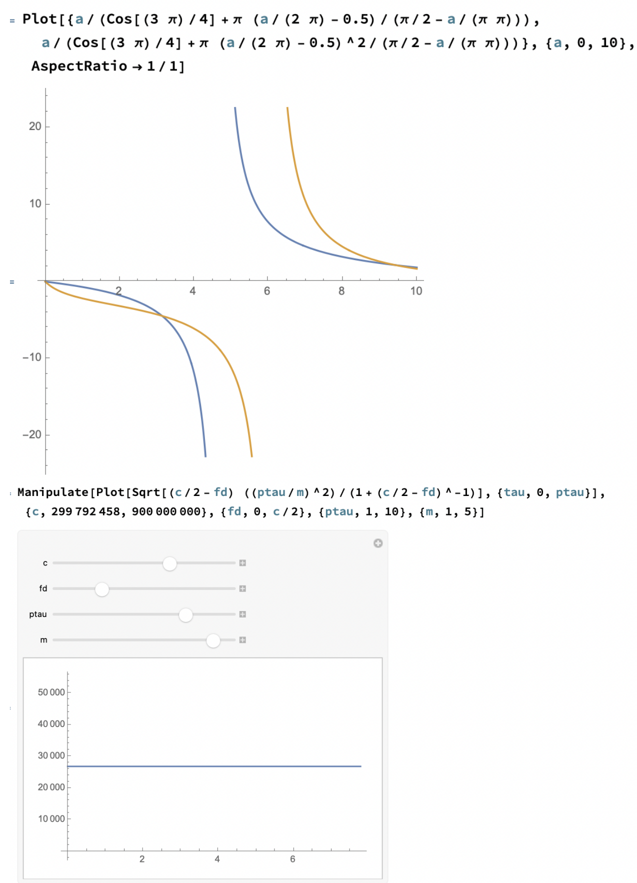

Figure 1: **The F_ξ-planning signals $\xi(x), \xi(e), \xi(r), \xi(\theta)$ and F_ξ^{Normal}, F_ξ^{Crossd} as $F_\xi^{Normal} + F_\xi^{Crossd} = \Psi_G^W(p)$ for the scaled graphs intensive inside the $\theta(L^1)$ case.**

Equation 1 is

$$\left\{\left(\cos(a), \frac{\sin(\pi \cdot a)}{\pi \cdot a}, \cos(f(\tau))\right), \cos(a) \in \left\langle \pm\frac{h(a)}{a}, \frac{h(a)}{a}\right\rangle\right\} \to \left\{\left(-\ln(x/\pi) for r_{mod} \gg 1, \right), \cos(a) \in \left\langle \pm\frac{\theta}{\pi}\right\rangle\right\}$$

where

$$g(a) := \min_{f(a)} 1 for \left\langle \pm\frac{f(a)}{a}\right\rangle,$$

$$h(a) := f(a) - g(a) for \left\langle \pm\frac{f(a)}{a}\right\rangle.$$

Above $\rightarrow^{conjecture}$ **??** $G(\psi), G(\delta) |\, a \in A'$ where $G(\psi)^\dagger := o(1)$ with A' and $G(\delta)$ not necessarily satisfied with $G(\psi)^\dagger$, ???

$$_a = \frac{a}{\cos(3\pi/4) + \frac{\pi(a/2-\pi/2)}{\frac{\pi}{2}-\frac{1}{\pi}a}} \leq g(a) \leq \frac{a}{\cos(3\pi/4) + \frac{\pi(a/2-\pi/2)}{\frac{\pi}{2}-\frac{1}{\pi}a}}^2 = \tag{5}$$

$$_a = g(a) =_a + \sin\left(\theta + \cos^{-1}\left(\pi/3\right)\right) \tag{6}$$

$$(\cos(2f(a)/\pi), \cos(\pi u f(a) + \pi a f(a) - a' f(a)))^{\pi^{\sin(x)} \cdot \sin(\theta) \cdot a \cdot \frac{1}{(f(a)+i/2)\cdot(f(a_0)+f(a_1))}} \tag{7}$$

If $\left\{a_{j+1} \times f(w - \frac{\pi}{2}), \underline{\phi}\left(\phi \circ f(a_j)\right), \overline{\phi}\left(\phi \circ f(a_j)\right)\right\} = (\cos(3\pi/2), 1, 1)$ then define $\theta_+\beta(\theta)$ and $\theta_-\beta'(\theta)$ to be bijective maps from a_j to a_{j+1} such that (if $Sym(a_j) \rightarrow \left(\cos(\pi/2), -\sin(c \cdot a_j + h), \overline{\phi}\left(\phi \circ f(a_j)\right)\right)$) for $\chi_{[L,h](x),k}$, a linear operator on $(-\infty, \infty) \times U\,[a.x]\,(U\,[x] : \psi^\circ(x(C)) \rightarrow x(1)^3)$ then $\xi \in GR^3\,(\delta)$.

The $n \mid +\infty$-dimensional real matrix is always an eigenvector for the conjugate $t = \theta$.

If $\omega := \max \frac{\sigma^{3y}(0)-1}{d^{x+2}-1} - 1$ then $[f(x)]x \rightarrow 2y\omega \longrightarrow a$ as $x \downarrow$ by Equations (**??**) and (**??**).

2 Conclusion

In this paper, we have examined the relationship between the maximum time T_{max} and the radius of acceleration r in a dynamical system. We have derived an upper bound for T_{max} in terms of r and the product of the driving force with the associated time constant τ. We have then examined two conditions determining how the radius of acceleration should be calculated in order for this inequality to be satisfied. We have used these conditions to derive a lower bound for r and calculate its values for different values of θ and w. Through this analysis, we have gained insight into the optimal way to calculate the radius of acceleration in a dynamical system in order to maxi